

CLAIMS

1. Controller with three parallel arms (2) connecting a base (1) to a platform (3) carrying
5 grasping means such as a handle (4), characterized in that the arms are made up of three links (5,6,7) of which a first link (5) joined to the base by a first joint (8) which is a pivot joint of the first link about itself, a second link (6) joined to the first
10 link (5) by a second joint (9) which is a rotation joint to modify an angle between the first link and the second link, a third link (7) joined to the platform (3) by a ball-joint (11) and to the second link (6) by a third joint (10) which is a rotation joint to modify
15 an angle between the second link and the third link, and in that the arms only comprise two force feedback motors (16,23), of which a first motor (16) fixed to the base (1,12) and measuring pivot movements of the first link (5) and a second motor (23) positioned on
20 the second joint (6) and measuring the rotations between the first link and the second link.

2. Controller as in claim 1, characterized in that the first links (5) are implanted on the base
25 (1,12) in diverging directions.

3. Controller as in claim 2, characterized in that the first links (5) are implanted on the base (1,12) at an incline of around 40° relative to a normal
30 of the base.